

A4
21 [reading and decoding the time code information
22 from the composite signal and supplying the decoded time
23 code information to a robot controller which controls the
24 movement of the arm of the robot along the predetermined
25 path of movement; and]

26 synchronizing the movement of the robot arm
27 along the predetermined path of movement with the
28 [decoded time code] video signal frame identification
29 information during the generation of video signals from
30 the storage medium such that the arm of the robot is
31 positioned by the robot controller in the same position
32 for each frame of video signal from the storage medium as
33 when each frame of video signal was initially generated
34 by the video camera.

Add the following new claims:

A5
Cont
1 11. The method of claim 10 wherein the step of
2 generating video signal frame identification information
3 comprises the step of:
4 generating time code information for each frame
5 of video signal generated by the video camera.

1 12. A method of generating video images
2 comprising:
3 programming a robot to repeatedly move an end
4 of a movable arm of the robot through a predetermined
5 path of movement;
6 operating a video camera to generate video
7 signals of visual images along the predetermined path of
8 movement from the camera during movement of the arm of
9 the robot along the predetermined path of movement;
10 storing the position coordinates of the robot
11 arm along the predetermined path of movement for each
12 distinct frame of the video signal generated by the video
13 camera on a video signal frame-by-frame basis;
14 storing the video signals on a storage medium
15 on a video signal frame-by-frame basis; and

16 synchronizing the movement of the robot arm
17 along the predetermined path of movement with each frame
18 of video signal during the generation of stored video
19 signals from the storage medium such that the arm of the
20 robot is positioned by the robot controller in the same
21 position for each frame of video signal operated from the
22 storage medium as when each frame of video signal was
23 initially generated by the video camera.

1 13. The method of claim 12 wherein the step of
2 storing the position coordinates of the robot arm further
3 comprises the steps of:

4 storing the position coordinates of the robot
5 arm in a memory; and

6 storing with each position coordinate a unique
7 video signal frame identification data.

1 14. The method of claim 13 wherein the step of
2 synchronizing further comprises the steps of:

3 generating video signals from the storage
4 medium on a frame-by-frame basis;

5 generating the video frame identification data
6 for each frame of video signal generated from the storage
7 medium;

8 accessing the memory to identify the position
9 coordinates of the robot arm associated with each
10 generated video signal identification data; and

11 moving the robot arm to the identified position
12 coordinates on a video signal frame-by-frame basis as the
13 video signals are generated from the storage medium.

REMARKS

Claims 1, 2 and 10 are rejected under 35 U.S.C.
103. Claims 3-9 are indicated as being allowable over
the prior art of record.

Accordingly, claims 3, 5, 7 and 9 have been
amended to place each of such claims in independent form